

ABSTRACT

A robot hand equipped with a function of gently pinching an object to be held is provided. A single degree of freedom joint for allowing bending or stretching is provided at a connecting portion between a distal phalange section 7 and a middle phalange section 9. Then, a driving mechanism for causing this joint to make a rotating motion within a predetermined angular range is provided. This driving mechanism 14 is constituted by a motor 15 for driving the joint and a speed reducer 17. The motor 15 is included in the middle phalange section 9 and generates a driving force for rotating the joint. The speed reducer 17 reduces a speed of the motor 15 and transmits the reduced speed to the joint. The joint and the driving mechanism 14 are configured so that the distal phalange section 7 is rotated relative to the middle phalange section 9 in two directions, namely, an inward direction and an outward direction within the predetermined angular range from a state where the distal phalange section 7 is arranged in a straight line with the middle phalange section.